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# Development of a state machine sequencer for the Keck Interferometer: evolution, development & lessons learned using a CASE tool approach

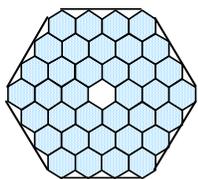
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June 21, 2004

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Jet Propulsion Laboratory  
California Institute of Technology



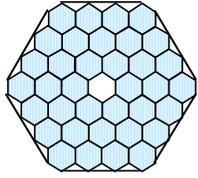


**KECK INTERFEROMETER  
PROJECT**

## Keck Interferometer



- 2 Keck 10m telescopes with full adaptive optics
- Wavelengths 1.2  $\mu\text{m}$  to 10  $\mu\text{m}$   
(AO operates in visible)
- Science: nulling, differential phase, astrometry, imaging
- First fringes with Keck Telescopes March, 2001

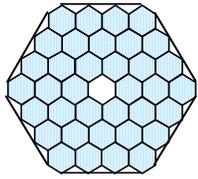


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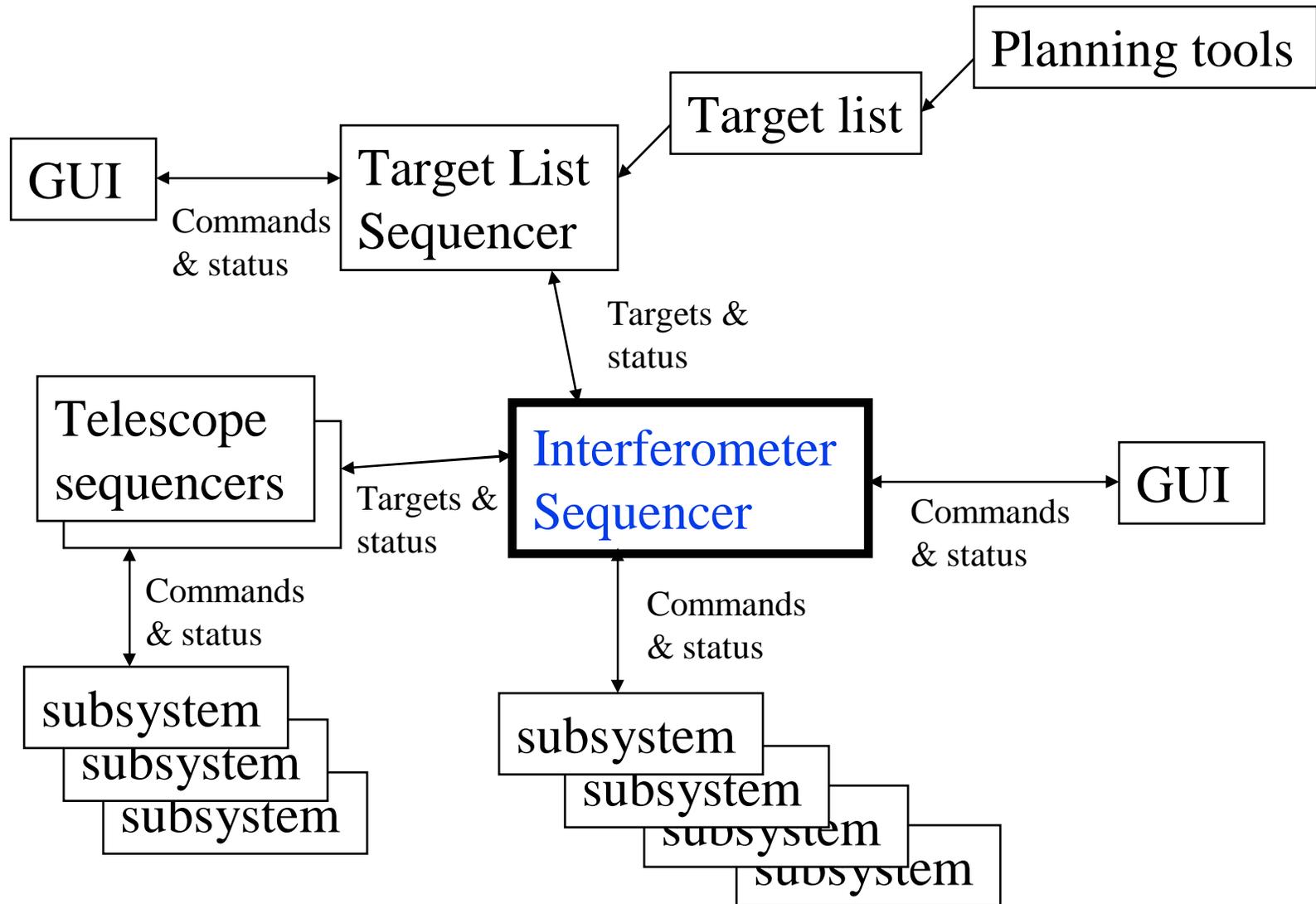
## What I will talk about

- Interferometer (IF) Sequencer within overall software
- What is the CASE Tool?
- Interferometer Major Components
- Rhapsody and IF Sequencer Design
  - Static Class and Harel Statechart Diagrams
- Lessons Learned





# Target/Observation Sequencing Hierarchy

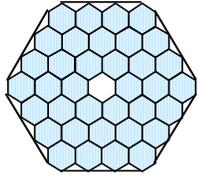


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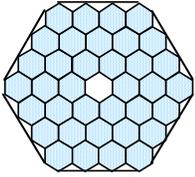
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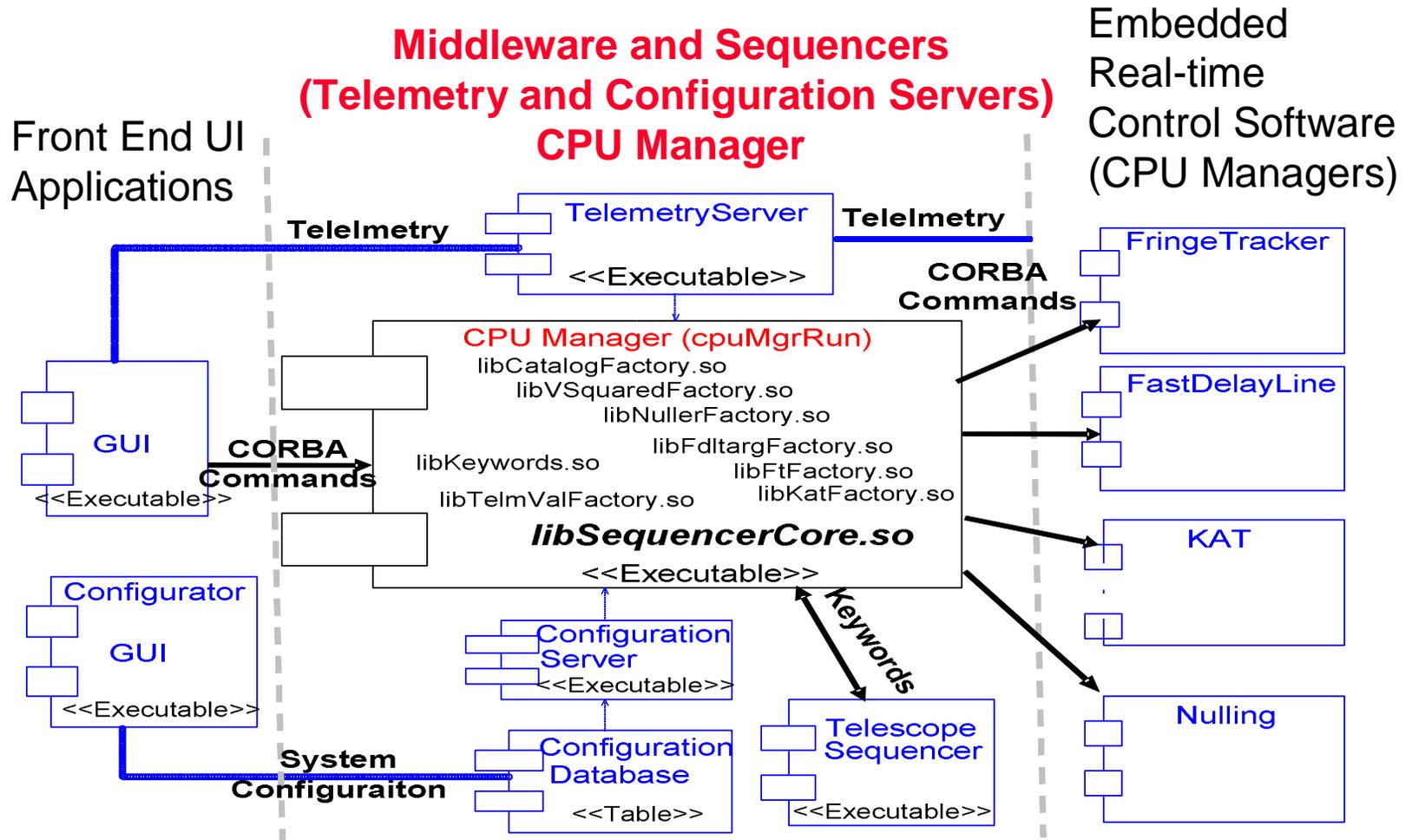
## Interferometer Sequencer

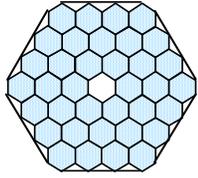
- Provide high-level control for observing
  - Send commands via CORBA to JPL RTC software
  - Control Keck Telescope Sequencers via Keywords API
  - Support Science modes: nulling, differential phase, astrometry, imaging (multi-baseline)
- ***State-machine classes running in separate threads***
- Multi-mode Science Ops
  - CPU Manager allows load, instantiate and desroy objects
  - Utilized Rhapsody internal shared infrastructure for state machine to state machine event passing
  - Configurable from common RTC database
  - New more flexible Python GUI using CORBA



# Component diagram of IF Sequencer Configuration with JPL RTC Toolkit

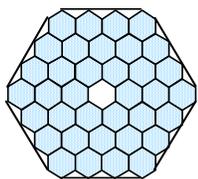
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## Rhapsody: What is the tool?

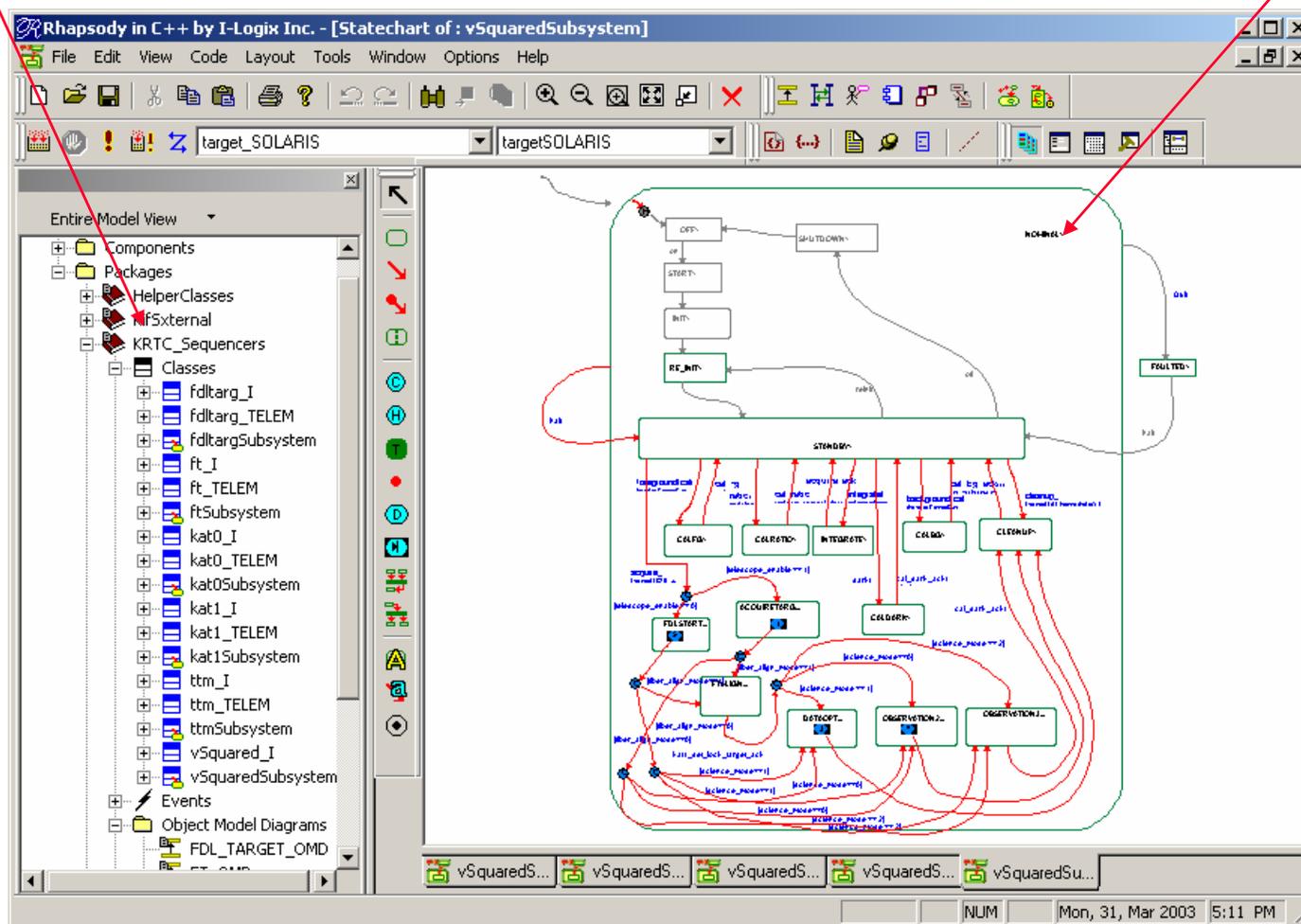
- It is a CASE (Computer Aided Software Engineering) Tool
- One uses UML (Unified Modeling Language) to design object structures and state machines
- The tool generates C++ code from the UML
- **Our main use of Rhapsody is to automatically generate multi-threaded state machine code!**
- One can specify state machine behavior for some classes using UML style state machine diagrams



# Screenshot showing Rhapsody CASE Tool

Model View

State Machine or Object Model Graphical Views



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# Interferometer Major Components



Beam Transport Optics  
(Coude Train)



Fringe Tracker (FATCAT)



Fast Delay Lines (FDL)

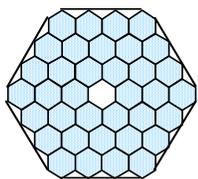


Angle Tracker (KAT)



Long Delay Lines (LDL)

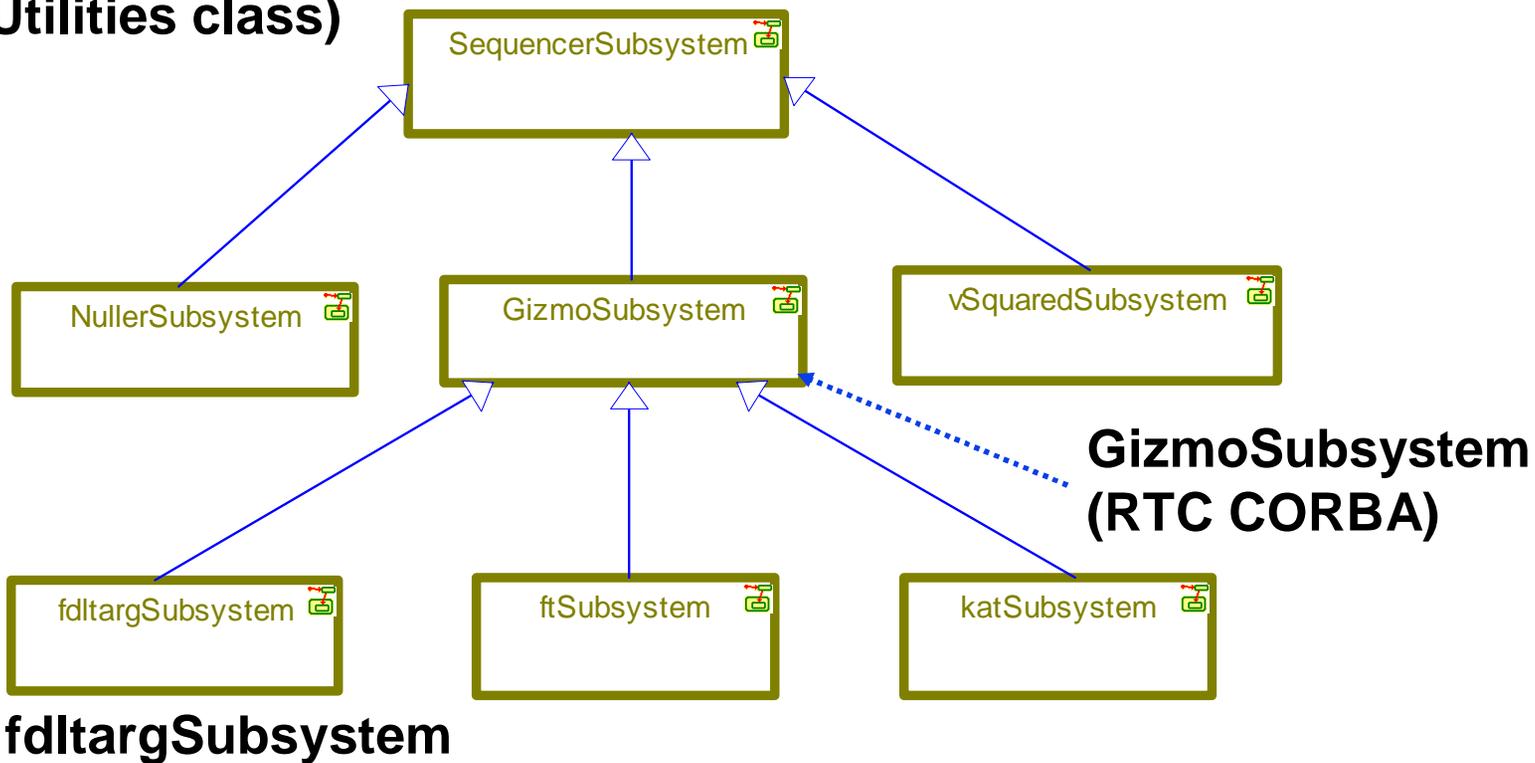


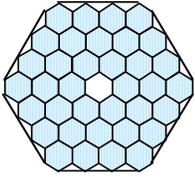


# Static Class Diagram of Subsystems Class Hierarchy

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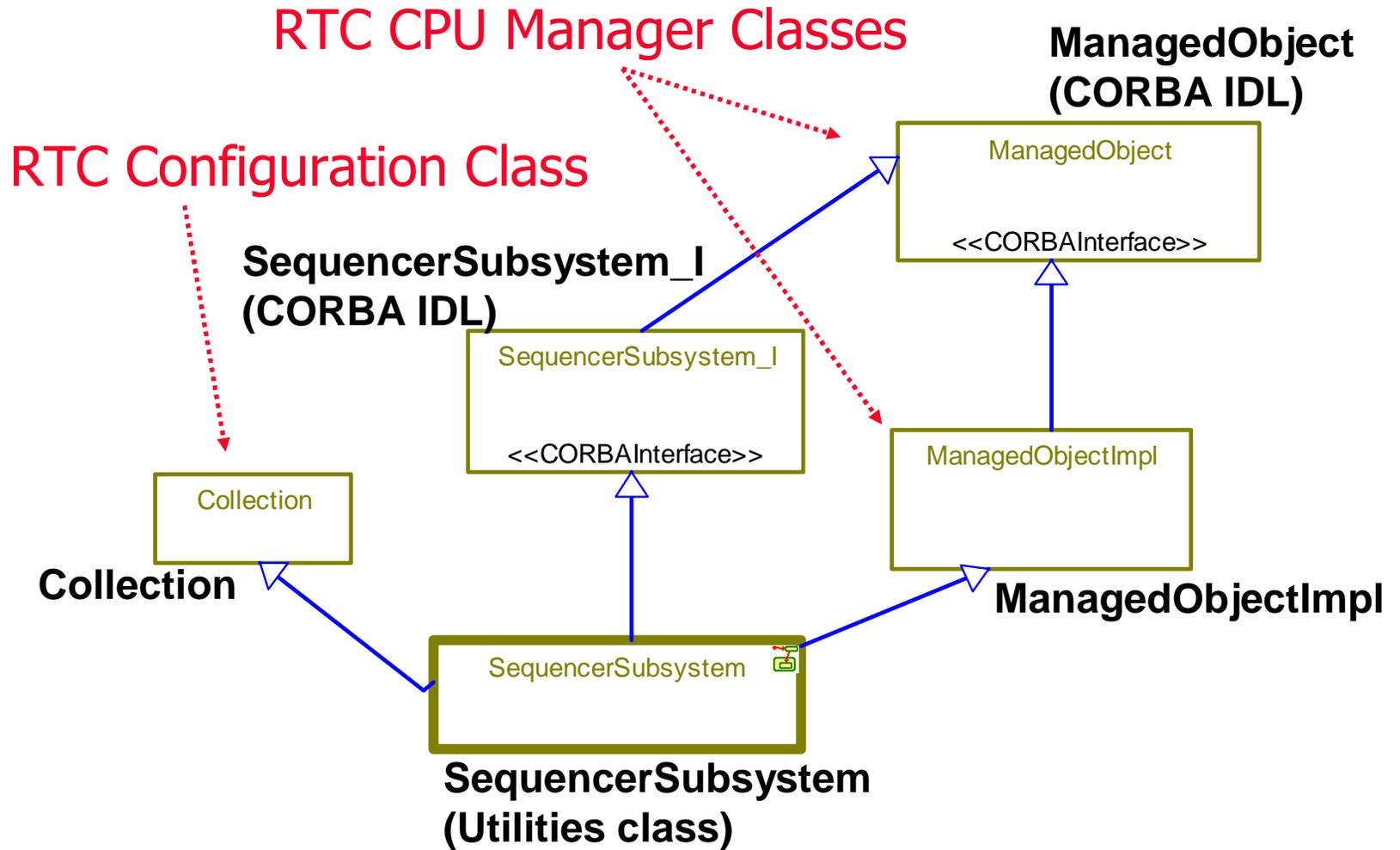
**SequencerSubsystem  
(Utilities class)**

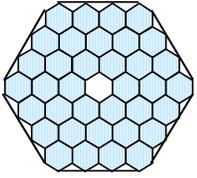




# SequencerSubsystem Utility Class Relationship to RTC Toolkit

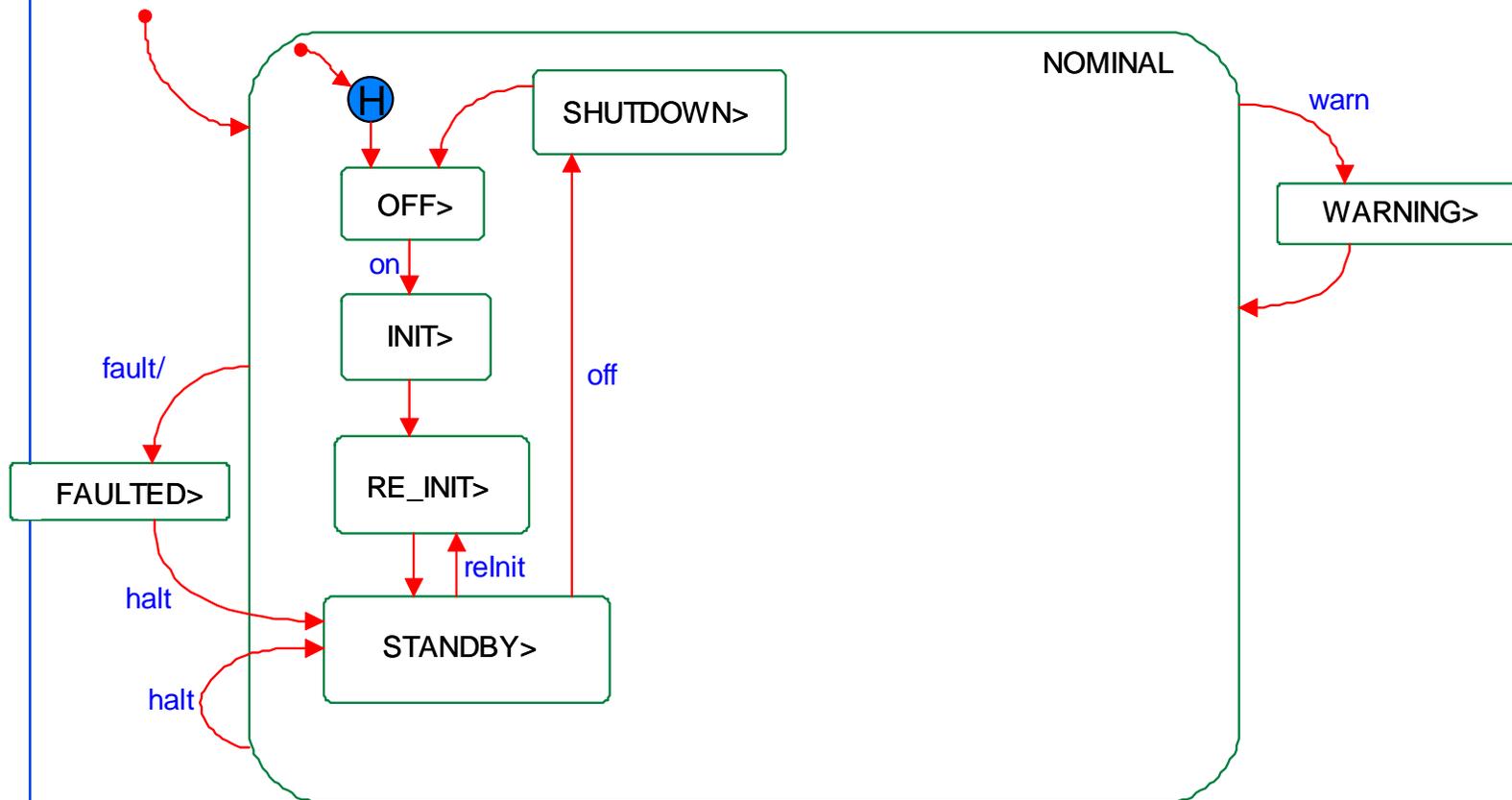
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# Harel State Machine-Based Design (Class)

- All state machines inherit this class  
**SequencerSubsystem (Utilities class)**



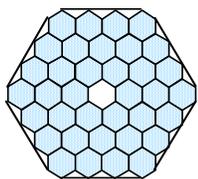
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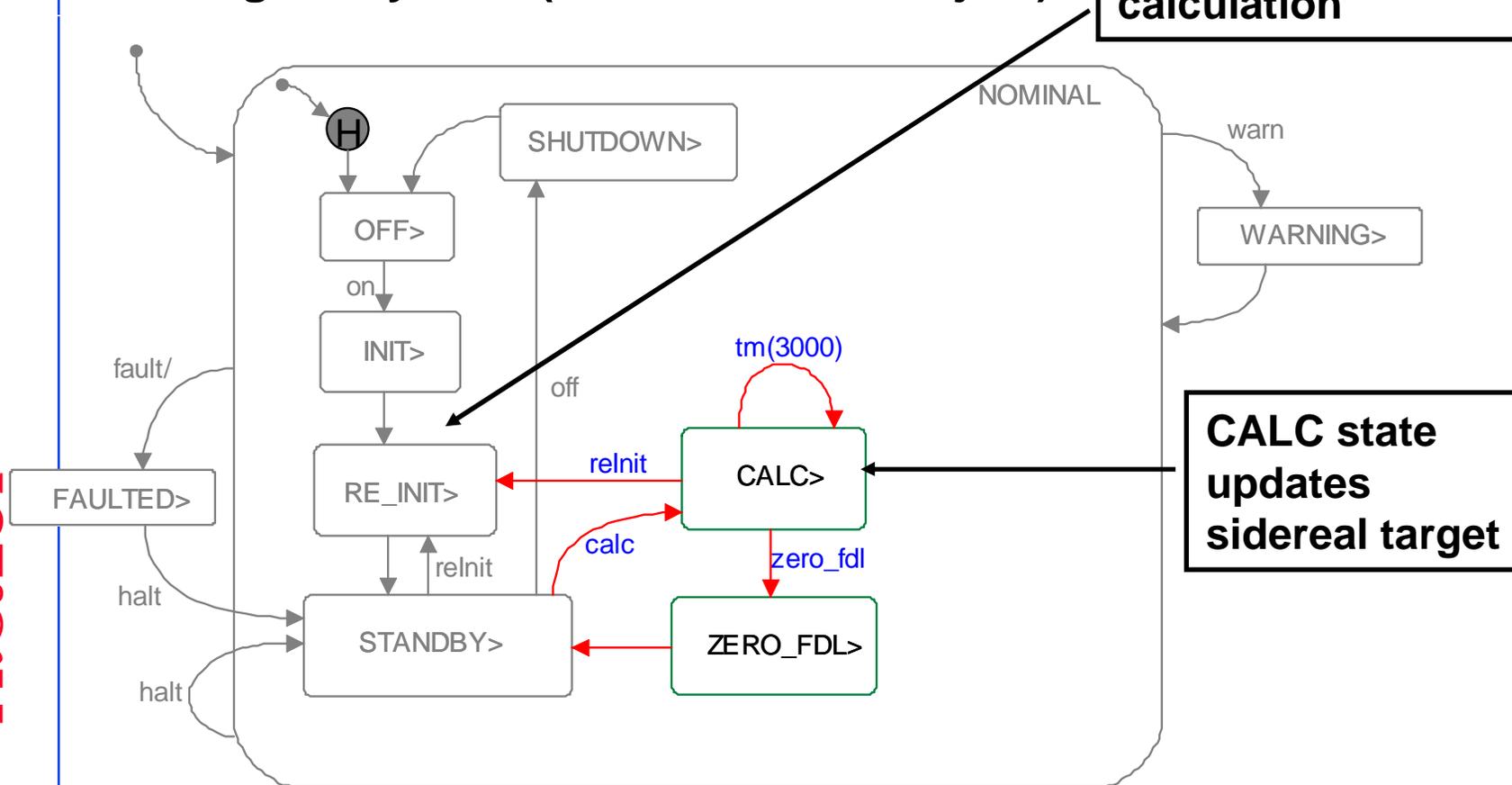
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# Fast Delay Line Target Generator Harel State Machine

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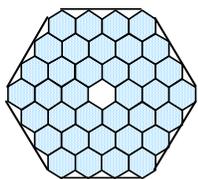
fdltargSubsystem (State Machine Object)



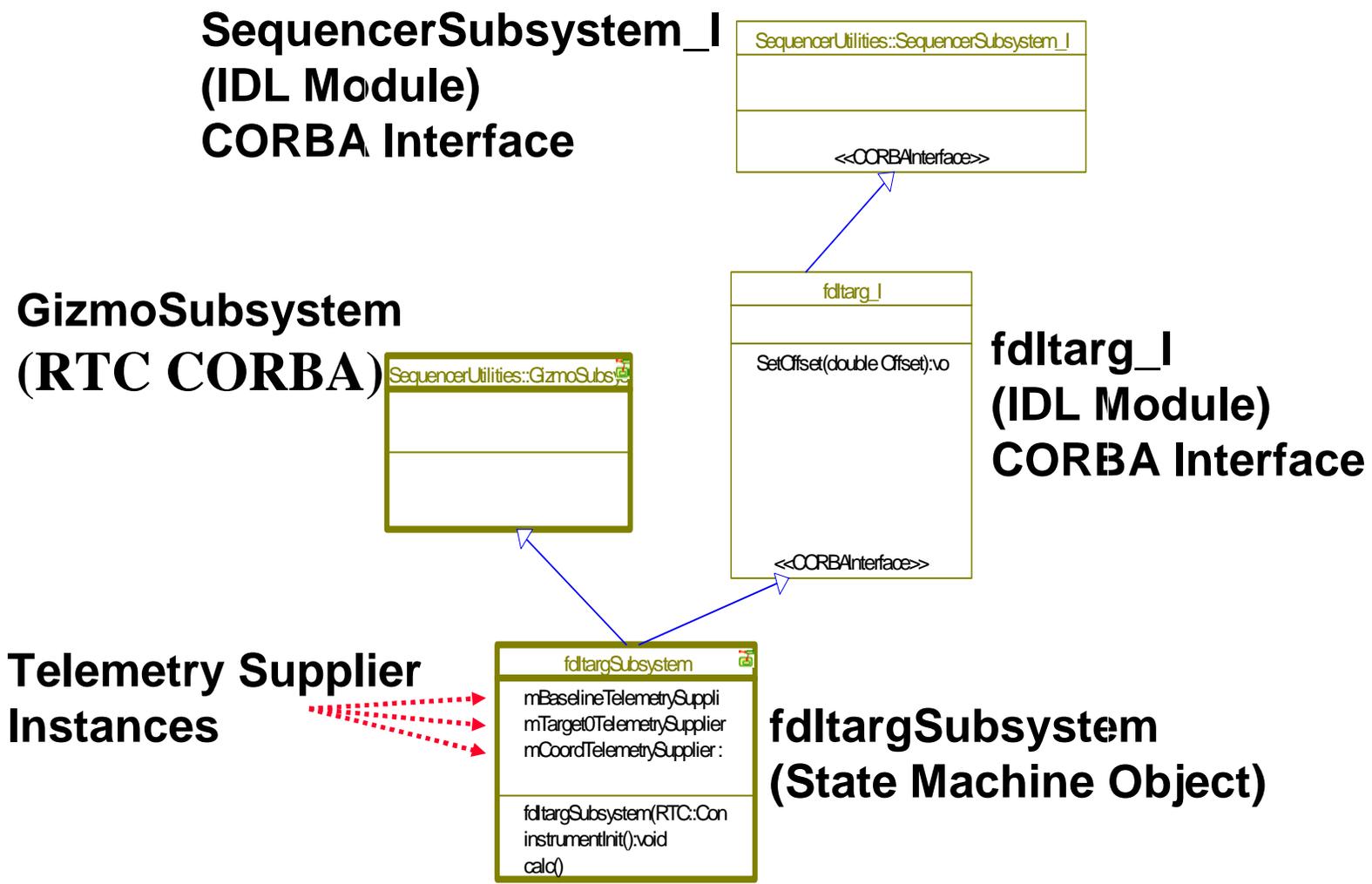
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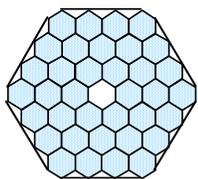
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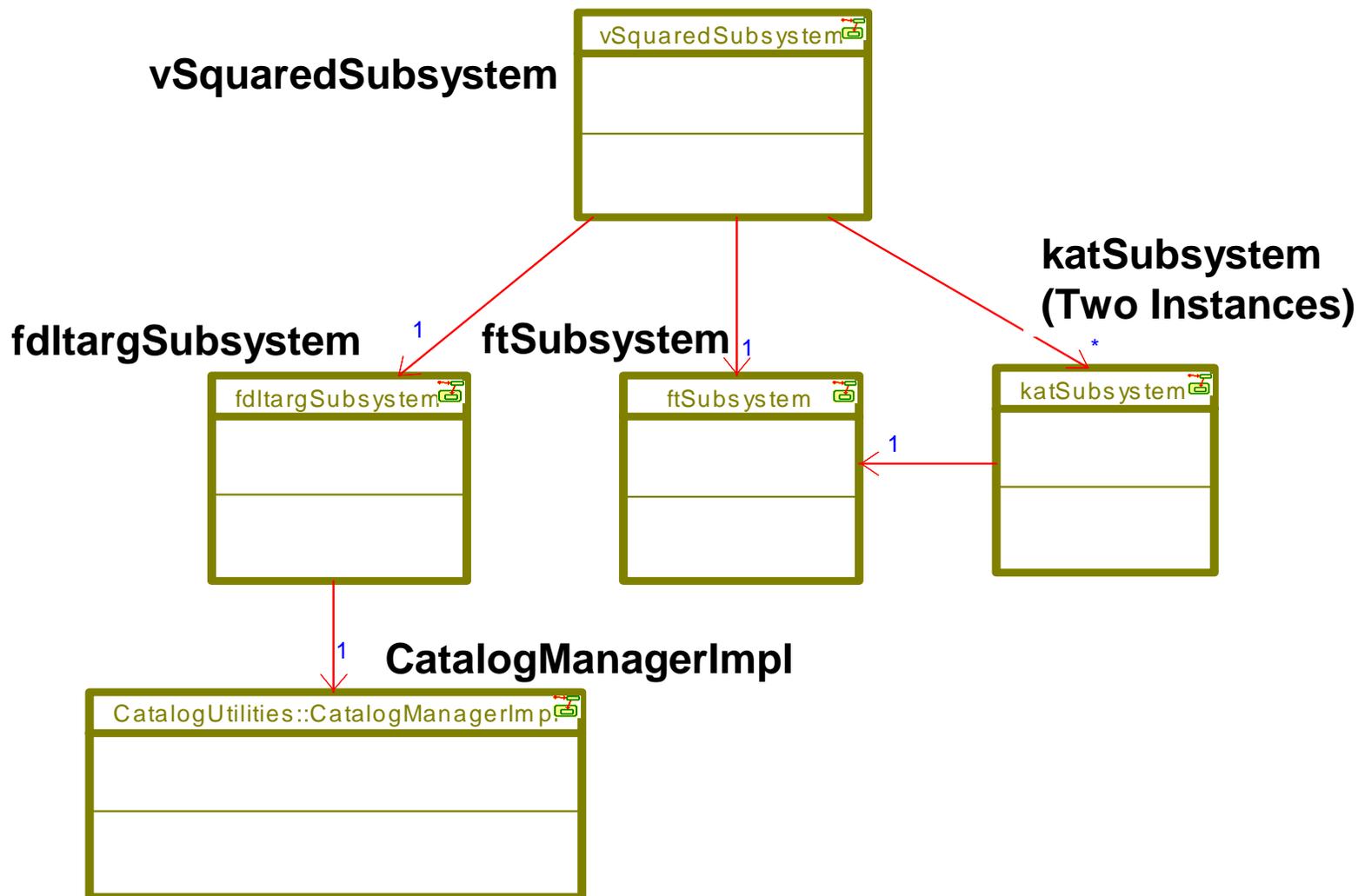
# Fast Delay Line Target Generator (fdltargSubsystem) Static Class Diagram

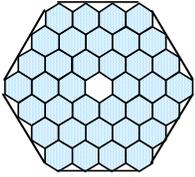




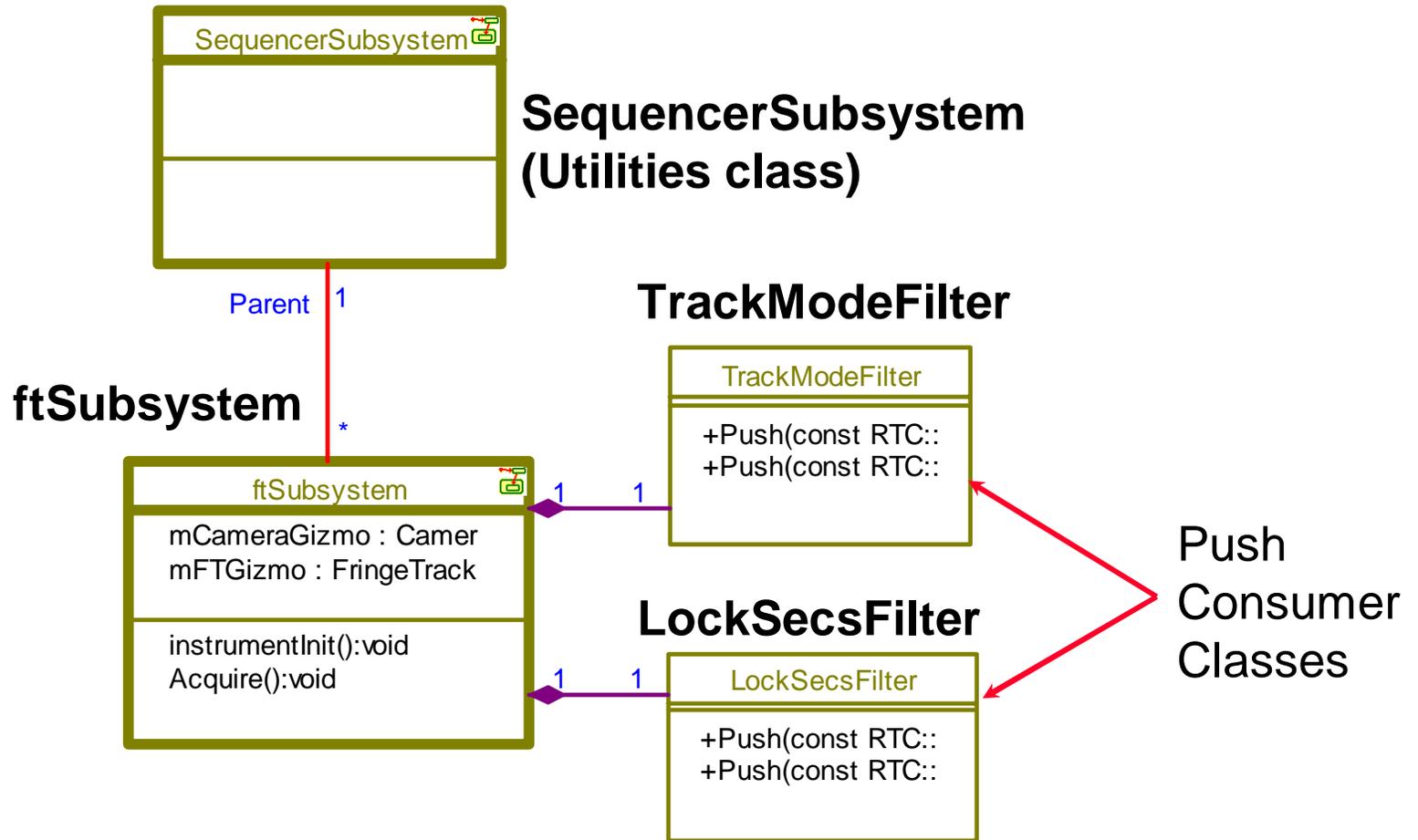
# Static Class Diagram of Subsystem Associations for Visibility Operation

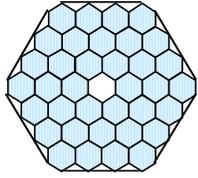
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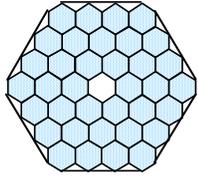
# Fringe Tracker UML (Shows Telemetry Consumers)





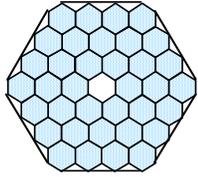
## Lessons Learned (1)

- 1) ***For CASE tool to be significantly beneficial requires an overall commitment and investment.***
  - a. Consider a process for development and then a tool.
- 2) Hard to integrate multiple infrastructures!
  - a. Even harder to integrate them into a CASE tool.
  - b. Ideally, on new projects try not to mix infrastructures.
  - c. Legacy code is inevitable so minimize mixing.
- 3) ***“Old programming habits die hard”***  
[Douglas Schmidt, UCLA Ext. 2002].
  - a. It is hard to learn graphical/coding UML methodology of the CASE tool environment if you have been a line-by-line coder for years.



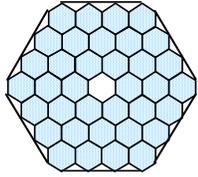
## Lessons Learned(2)

- 4) ***Maintainability of code is vastly improved.***
  - a. C++ code is coupled to a UML graphical model so it is more understandable.
  - b. Automatically limits the amount of reverse engineering of code required later in software lifecycle!
  
- 5) ***Standardized auto-generated code leads to better infrastructure.***
  - a. Design can be rapidly changed graphically with only a minimum amount of coding required.
  
- 6) Templates were not included with the Rhapsody case tool so we implemented them externally and hooked them into the tool. This is a kludge and is confusing to a new developer. This effectively defeats rule 4 above.



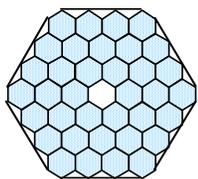
## Lessons Learned (3)

- 7) The urge to use many of Rhapsody's framework features has sometimes overwhelmed the wiser inclination to use more standardized tools such as the STL (C++ Standard Template Library).
- 8) ***Features in a tool may look good during a sales demo, but be careful!***
- 9) When starting, one should evaluate and not guess at a CASE tool to use; there are lots of choices today.
- 10) Version control of UML models can be problematic even between only a few developers.



## Summary

- Implemented a multi-threaded state machine based, high-level, control capability for the Keck Interferometer
- State-machine classes have been designed to be highly configurable and flexible while reusing a basic state-machine initialization and error handling scheme
- CASE tool approach is superior to hand line-by-line coding
  - Improved maintenance over the life-cycle is realized
  - Dealing with third party infrastructures outside of the Rhapsody tool is problematic at first
  - After significant effort at integration it becomes easy to graphically add states and additional software architecture
- Rhapsody is an excellent tool, especially for state machine design and the problem fits nicely into the infrastructures provided by I-logix and the JPL developed RTC toolkit



# Interferometer Sequencer User Interface

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Selected  
observation  
record

Current  
observation  
& baseline  
vector

Optional  
State Machine  
Control  
Panel

| StarID | Hr | Min | Sec | Deg | Min | Sec  | pmRA | pmDec | Vmag | Kmag | BVColor |     |     |     |     |     |
|--------|----|-----|-----|-----|-----|------|------|-------|------|------|---------|-----|-----|-----|-----|-----|
| HDC0   | 02 | 00  | 00  | +19 | 49  | 36.0 | 0.0  | 0.0   | 5.8  | 5.1  | 0.4     | FOV | 0.0 | xxx | xxx | trg |
| HDC1   | 08 | 00  | 00  | +19 | 49  | 36.0 | 0.0  | 0.0   | 5.8  | 5.1  | 0.4     | FOV | 0.0 | xxx | xxx | trg |
| HDC2   | 8  | 30  | 00  | +19 | 49  | 36.0 | 0.0  | 0.0   | 5.8  | 5.1  | 0.4     | FOV | 0.0 | xxx | xxx | trg |
| HDC3   | 9  | 00  | 00  | +19 | 49  | 36.0 | 0.0  | 0.0   | 5.8  | 5.1  | 0.4     | FOV | 0.0 | xxx | xxx | trg |
| HDC4   | 9  | 30  | 00  | +19 | 49  | 36.0 | 0.0  | 0.0   | 5.8  | 5.1  | 0.4     | FOV | 0.0 | xxx | xxx | trg |
| HDC5   | 10 | 00  | 00  | +19 | 49  | 36.0 | 0.0  | 0.0   | 5.8  | 5.1  | 0.4     | FOV | 0.0 | xxx | xxx | trg |
| HDC6   | 10 | 30  | 00  | +19 | 49  | 36.0 | 0.0  | 0.0   | 5.8  | 5.1  | 0.4     | FOV | 0.0 | xxx | xxx | trg |
| HDC7   | 11 | 00  | 00  | +19 | 49  | 36.0 | 0.0  | 0.0   | 5.8  | 5.1  | 0.4     | FOV | 0.0 | xxx | xxx | trg |
| HDC8   | 11 | 30  | 00  | +19 | 49  | 36.0 | 0.0  | 0.0   | 5.8  | 5.1  | 0.4     | FOV | 0.0 | xxx | xxx | trg |

Generated  
Delay Line  
Sidereal  
Targets

Sequencer  
observing  
controls

Text Status

